

Abstract

A method for providing control variables (a_m , a_b) for guiding a motor vehicle as a function of input quantities (v , e_l , e_k , d_i , v_{ri} , ϕ_i), which represent the traffic situation, and as a
5 function of dynamically changeable parameters, characterized in that a single evaluation quantity (g) is formed from a set of a plurality of input quantities and a plurality of the parameters are determined on the basis of the same evaluation quantity.

10 Figure 1